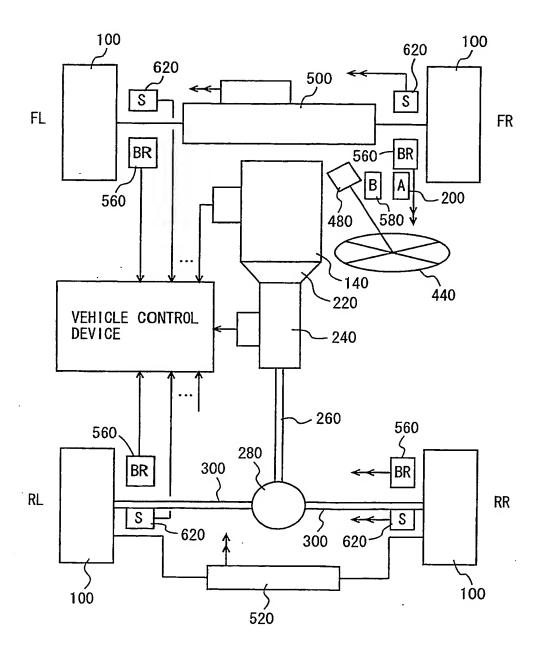
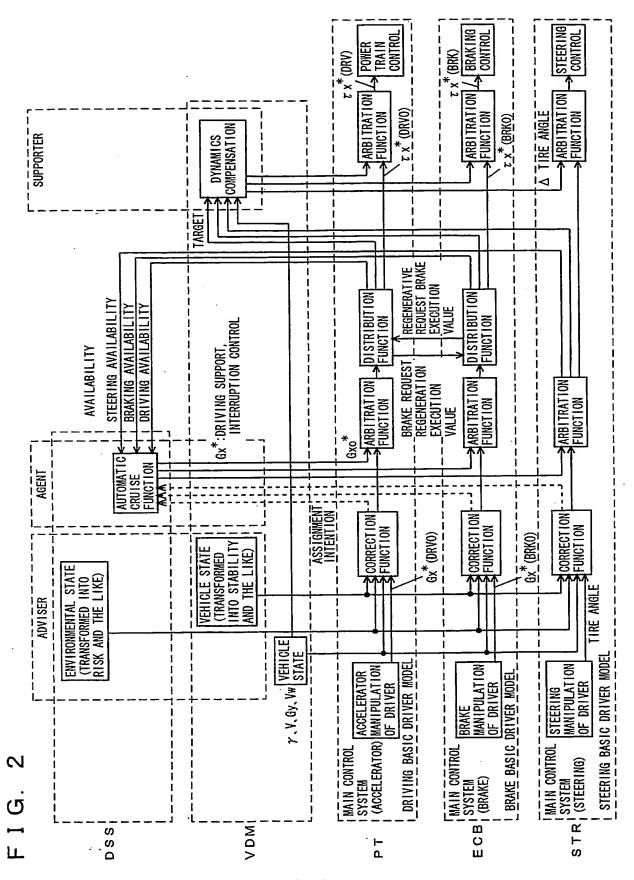
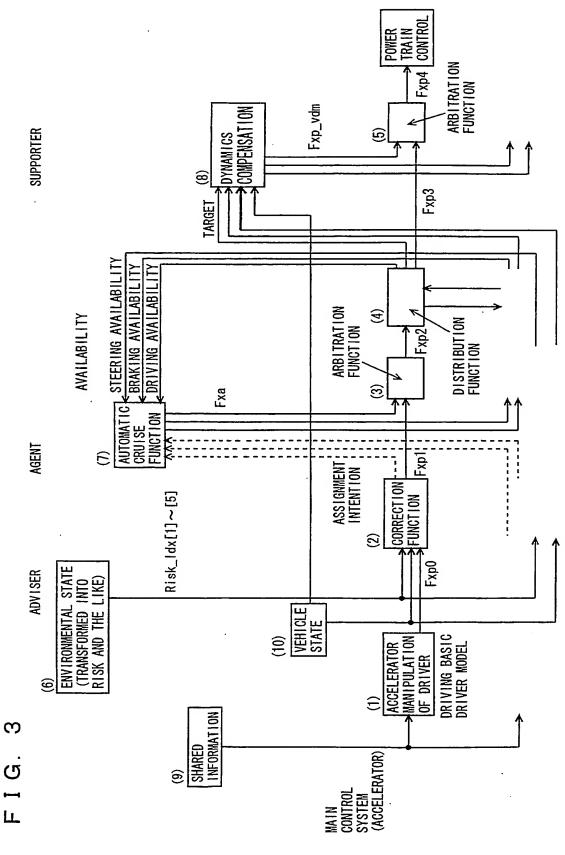
WO 2005/063523 PCT/JP2004/018967

F I G. 1





WO 2005/063523 PCT/JP2004/018967



(4) DISTRIBUTION (7) Fxa, available\_status flag (3) ARBITRATION (2) CORRECTION | (6) Risk\_Idx[n] (1) DRIVING BASIC DRIVER MODEL ACCELERATOR WEDAL VEHICLE SPEED F (9) SHARED INFORMATION 4/10

A | (8) Fxp\_vdm, vdm\_status flag

(7) · (8) Fxp\_avail |

(5) ARBITRATION

FxB

Fxp2

max (Fxp1, Fxa)

Fxp1=f(Fxp0, Risk\_ldx[n])

f (pa, spd, ig) Fxp0=

Fxp3←f (Fxa, Fxp2) FxB=f (Fxa, Fxp2)

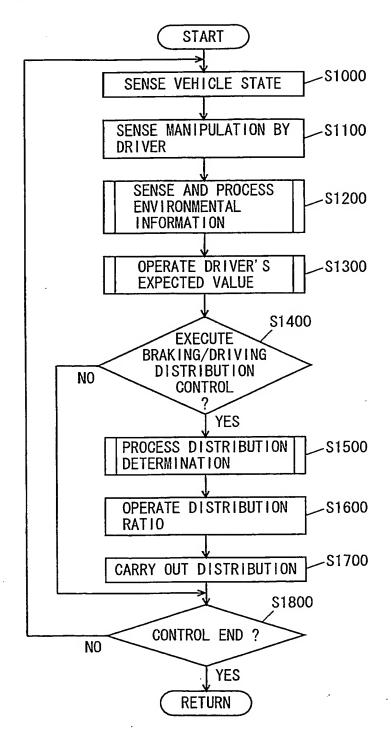
 $(7) \cdot (8) \quad \land \mid (8) \text{Fxb\_vdm, vdm\_status flag}$  Fxb\\_avail  $\mid \mid (8) \text{Fxb\_vdm, vdm\_status}$ (5) ' ARB I TRATION Fxb4= max (Fxb3, Fxb\_vdm) Fxb3 (7) Fxba, available\_status flag Fxb2 (3) ' ARBITRATION (2) ' CORRECTION Fxb1=f (Fxb0, (6) Risk\_Idx[n] (1)' BRAKING BASIC DRIVER MODEL f (ba, spd, Gy) Ŋ (9) SHARED INFORMATION 5/10

<u>G</u> ட

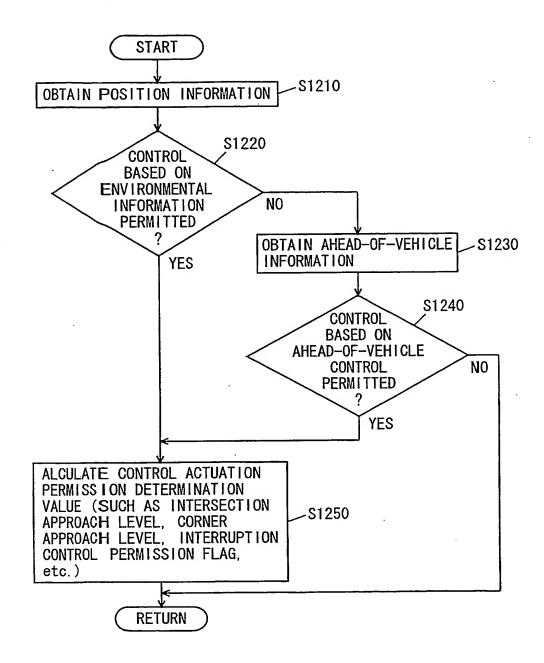
 $|\longrightarrow \text{STERING} \\ |_{\Delta 4} \text{control}$  $(7) \cdot (8) \land (8) \land vdm, vdm\_status flag \land avail$ (5) "ARB | TRAT | ON (7) Δa, available\_status flag (3) "ARBITRATION (2) "CORRECTION | (6) Risk\_| dx [n] 9 F G 6/10

WO 2005/063523 PCT/JP2004/018967

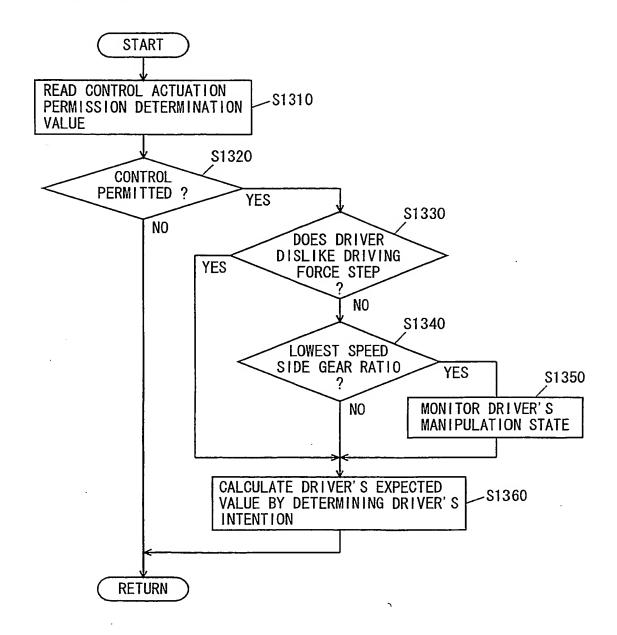
F I G. 7



## FIG. 8



F I G. 9



## FIG. 10

